

FIG. 1

```

class ClassA{
public:
    void Function1(void) {...};
    void Function2(void) {...};
};

class ClassB : public ClassA{
public:
    void Function2(void) {...};
    void Function3(void) {...};
};

class ClassC{
public:
    virtual void Function1(void)=0;
};

class ClassD: public ClassC{
Public:
    void Function1(void);
};

main(void){
    ClassA ObjectA;
    ObjectA.Function1();
    ObjectA.Function2();

    ClassB ObjectB;
    ObjectB.Function1();
    ObjectB.Function2();
    ObjectB.Function3();

    ClassA *PointerA;
    PointerA=&ObjectB;
    PointerA->Function1();
    PointerA->Function2();
    //PointerA->Function3(); //Because ClassA does not have Function3,
                           //the compiler outputs an error.

    //ClassC ObjectC; //Because ClassC has a pure virtual function,
                    //an object cannot be produced.
    //Therefore, the compiler outputs an error.

    ClassD ObjectD;
}

```

FIG. 2

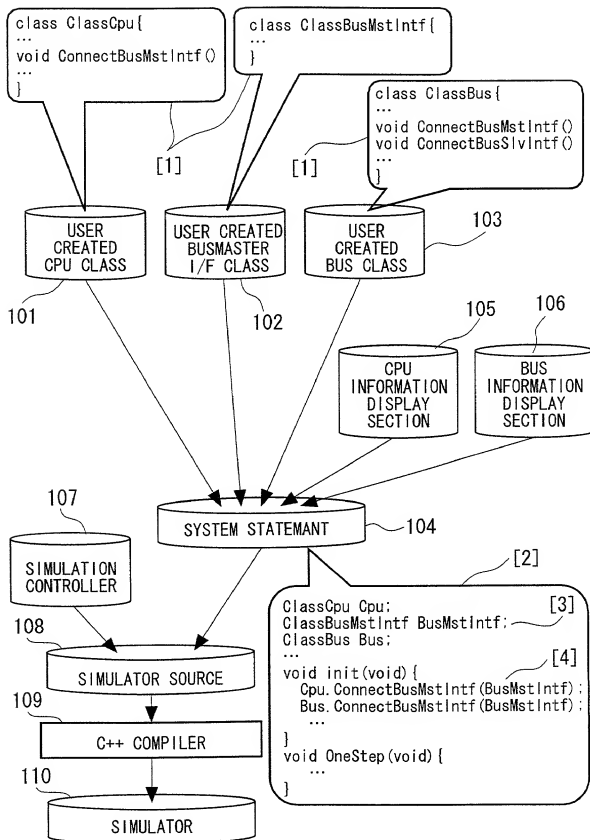


FIG. 3A

EXAMPLE OF DESCRIPTION IN C++

```
class ClassA{
    ...
    void GetData(int i);
    ...
};

class ClassB{
    ...
    ClassA *PointerA;
    void ConnectA(ClassA *a)
    {PointerA=a};
    void OneStep(void) {
        ...
        ...=PointerA->GetData(i);
        ...
    }
};

main() {
    ClassA ObjectA;
    ClassB ObjectB;
    ObjectB. ConnectA(&ObjectA);
    ...
    ObjectB. OneStep();
    ...
}
```

FIG. 3B

SCHEMATIC DIAGRAM

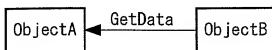


FIG. 4

CLASS	PROPERTY
CmComponent	general circuit
CmSyncModule	circuit operating synchronously with clock
CmBusMaster	main section of bus master
CmBusSlave	main section of bus slave
CmBusMstIntf	bus master interface
CmBusSlvIntf	bus slave interface
CmBusSystem	bus
CmCpu	CPU
CmMemory	memory
CmHier	hierarchy of a circuit containing the bus

FIG. 5

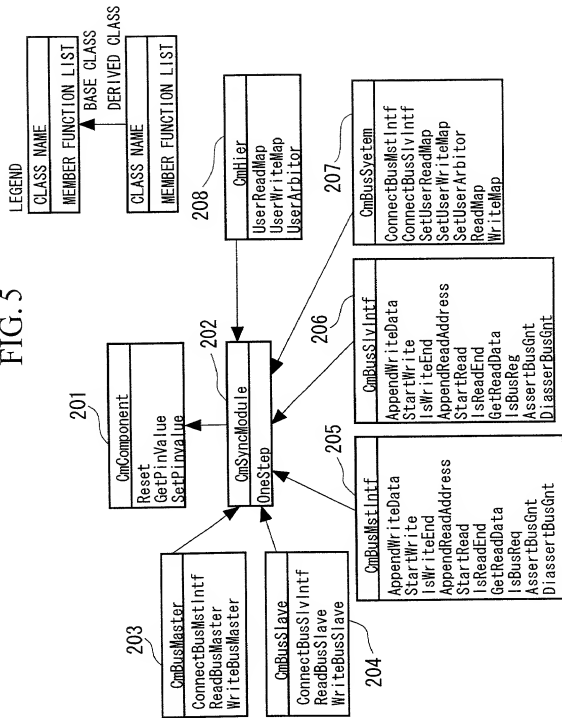
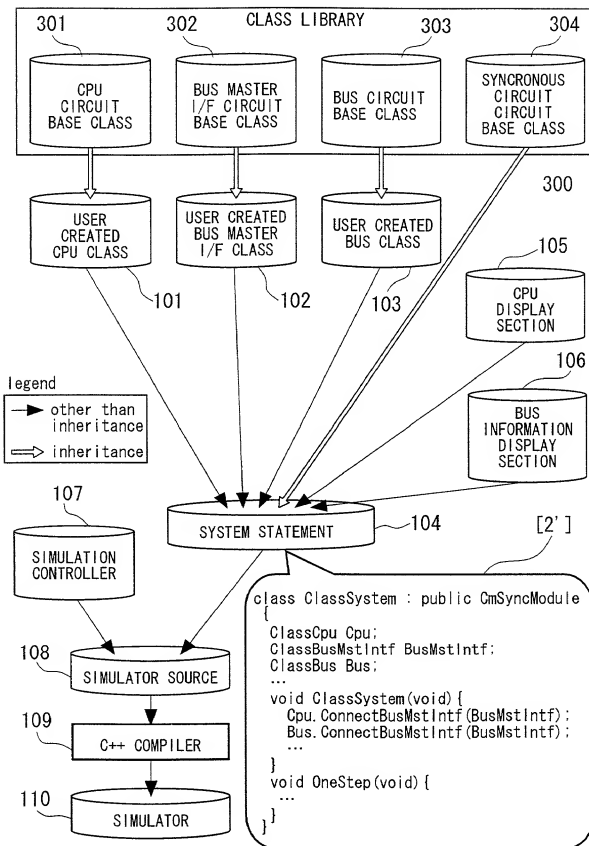


FIG. 6

ACTUAL CIRCUIT CLASS	CIRCUIT BASE CLASS
CmPciBusMstIntf	CmBusMstIntf
CmPciBusSivIntf	CmBusSivIntf
CmPciBusSystem	CmBusSystem
CmV850	CmCpu

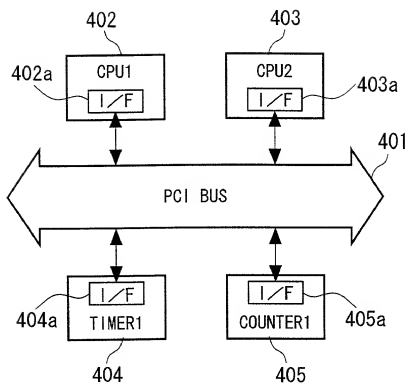
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FIG. 7



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FIG. 8



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FIG. 9

```

class ABC : public CmHier { [1]
    // Create a PCI bus in a system ABC. [2]
    CmPciBusSystem PciBusSystem; [3]

    // Create two CPU, which are Cpu1, and Cpu2, in the system ABC
    CmCpu Cpu1, Cpu2;

    // Because Cpu1, and Cpu2 are bus masters, [4]
    // a bus master interface for connecting Cpu1 and Cpu2 to the bus
    // are created in the system ABC.
    CmPciBusMstIntf Cpu1BusMstIntf, Cpu2BusMstIntf;

    // Create a circuit Timer1 in the system ABC. [5]
    CmTimer Timer1;

    // Because Timer1 is a bus slave, [6]
    // a bus slave interface for connecting Timer1 to the bus
    // is created in the system ABC.
    CmPciBusSlvIntf Timer1BusSlvIntf;

    // Create a circuit Counter1 in the system ABC. [7]
    CmCounter Counter1;

    // Because Counter1 is a bus slave, [8]
    // a bus slave interface for connecting Counter1 to the bus
    // is created in the system ABC.
    CmPciBusSlvIntf Counter1BusSlvIntf;

    ... // Other modules are described (omitted). [9]
}
    
```

FIG. 10

```

// UserBusReadMap describes a bus read map. [1]
// The return value is structure RDATA
// RDATA.Status returns 0 on success and 1 on failure.
// RDATA.Data returns the read value on success.
// ULONG is a signal value of 32 bits.
RDATA UserBusReadMap(ULONG address, int byte_count) {
// Based on address, the circuit from which the value
// is to read is determined.
// Execute the read function of the bus slave interface of the circuit
RDATA v; [2]

// Read values from addresses 100 to 200 into Timer1
if ((100 <= address) && (address < 200)) { [3]

// Designate the address to be read [4]
Timer1BusSlvIntf.AppendReadAddress(0, address-100,
byte_count);

// Read the value. [5]
Timer1BusSlvIntf.StartRead(0);

// Check whether the reading is successful [6]
if (Timer1.IsReadEnd(0)) {

// The reading is successful. [7]
v.Status = 0;

// Extract the read value. [8]
v.Data = Timer1BusSlvIntf.GetReadData(0);
return v;
} else {

// The reading failed. [9]
v.Status = 1;
return v;
}

// Read the values from addresses 200 to 300 in Counter1.
else if ((200 <= address) && (address < 300)) {
// The similar steps as those for [11]
// Timer1 are repeated in the following.
} else if ... // The same steps are repeated for the other circuits
} [12]

```

FIG. 11

```

// UserBusWriteMap describes a bus write map. [1]
// The return value is int.
// Returns 0 on success, and 1 on failure.
// ULONG is a signal value of 32 bits.
int UserBusWriteMap(ULONG address, ULONG data,
    int byte_count) {
    // Write a value, based on address. [2]
    // Determine a circuit, and execute the write function
    // of the bus slave interface of the determined circuit. [3]
    // Write the values into addresses 100 to 200 of Timer1
    if ((100 <= address) && (address < 200)) { [4]
        // Designate the address into which the value to be written.
        Timer1BusSlvIntf.AppendWriteData(0, address-100,
            data, byte_count);
        // Write the value. [5]
        Timer1BusSlvIntf.StartWrite(0);
        // Check whether the writing is successful. [6]
        if (Timer1.IsWriteEnd(0)) {
            // The writing is successful. [7]
            return 0;
        } else {
            //The writing failed. [8]
            return 1;
        }
    }
    // Write the values into the addresses 250 to 350 from Counter1.
    //The addresses are different for the reading and the writing.
    else if ((250 <= address) && (address < 350)) {
        // In the following, similar steps to those for [9]
        // Timer1 are repeated. [10]
    } else if ... // Similar steps are repeated [11]
    // for the other circuits.
}

```

FIG. 12

```
// UserArbitor describes an arbiter. [1]
// The return value is void (no return value).
// The permission to use the bus is directly given to
// the bus master interface.
void UserArbitor(void) {

    // The request to use the bus is directly extracted [2]
    // from the bus master interface.
    int Cpu1BusReq = Cpu1BusMstIntf.IsBusReq();
    int Cpu2BusReq = Cpu2BusMstIntf.IsBusReq();

    // Cpu1 is preferred to Cpu2. [3]
    if (Cpu1BusReq) {

        // Allow Cpu1 to use the bus when Cpu1 requests to use the bus [4]
        // even if the Cpu2 requests to use the bus
        Cpu1BusMstIntf.AssertBusGnt();
        Cpu2BusMstIntf.DiassertBusGnt();

    } else if (Cpu2BusReq) {

        // Allow Cpu1 to use the bus when Cpu1 requests to use the bus [5]
        // even if the Cpu2 requests to use the bus
        Cpu1BusMstIntf.DiassertBusGnt();
        Cpu2BusMstIntf.AssertBusGnt(); [6]

    } else {
        Cpu1BusMstIntf.DiassertBusGnt(); [7]
        Cpu2BusMstIntf.DiassertBusGnt();
    }
}
```

FIG. 13

```
// ABC(void) is a function (constructor)
// when creating the object of the system ABC. [1]
ABC(void) {

    // Connect the bus with the circuits. [2]
    Cpu1.ConnectBusMstIntf(&Cpu1BusMstIntf);
    Cpu2.ConnectBusMstIntf(&Cpu2BusMstIntf);
    Timer1.ConnectBusSlvIntf(&Timer1BusSlvIntf);
    Counter1.ConnectBusSlvIntf(&Counter1BusSlvIntf);
    PciBusSystem.ConnectBusMstIntf(&Cpu1BusMstIntf);
    PciBusSystem.ConnectBusMstIntf(&Cpu2BusMstIntf);
    PciBusSystem.ConnectBusSlvIntf(&Timer1BusSlvIntf);
    PciBusSystem.ConnectBusSlvIntf(&Counter1BusSlvIntf);
    ... // Describe the other circuits (omitted). [3]

    // Designate an address map. Register the created address map
    // in PciBusSystem. Thus, PciBusSystem can use
    // the created address map.
    PciBusSystem.SetUserReadMap(UserReadMap);
    PciBusSystem.SetUserWriteMap(UserWriteMap); [4]
}

// OneStep describes the operation of the system ABC
// within one unit time. [5]

void OneStep(void) { [6]
    // The system ABC is operated by the arbitrary behaviors
    // of the components. Accordingly, in the level of the
    // system ABC, the respective components in the system
    // are simply operated in one unit time.
    PciBusSystem.OneStep(); [7]
    // Although the bus does not require
    // the clock because the bus is a signal line, the clock
    // is given to the bus in order to extract data synchronously
    // with the clock for debugging.

    Cpu1BusMstIntf.OneStep();
    Cpu2BusMstIntf.OneStep(); [8]
    Timer1BusSlvIntf.OneStep();
    Counter1BusSlvIntf.OneStep();
    Cpu1.OneStep();
    Cpu2.OneStep();
    Timer1.OneStep();
    Counter1.OneStep();
    ... // The other circuits are operated. [9]
}
```

FIG. 14

```
class CmComponent {
    // Usage: describe a sequence circuit with a clock.

public:
    virtual void Reset(void) = 0;
        // Usage: asynchronous resetting.
    virtual RDATA GetPinValue(int no) {
        // Usage: return the signal value at the terminal number "no".
    }

    virtual int SetPinValue(int no, ULONG data);
        // Usage: apply data at the terminal number "no".
    };
};
```

FIG. 15

```
class CmSyncModule : public CmComponent {
    // Usage: describe a sequence circuit having a clock.
    // Note: CmSyncModule uses Reset, GetPinValue, and SetPinValue
    //       defined in CmComponent as are.

public:
    virtual void OneStep(void) = 0;
        // Usage: operate the circuit by one step.
    };
};
```

FIG. 16

```
class CmBusMaster : public CmSyncModule {
    // Usage: describe the main section of the bus master.

public:
    virtual void ConnectBusMstIntf(CmBusMstIntf *bus_mst_intf) {
        // Usage: connect the circuit to the bus master interface.
    }

    virtual RDATA ReadBusMaster(ULONG address,
        int byte_count) = 0;
        // Usage: read a value from the circuit to the bus.

    virtual int WriteBusMaster(ULONG address, ULONG data,
        int byte_count) = 0;
        // Usage: write a value from the object into the bus.
};
```

FIG. 17

```
class CmBusSlave : public CmSyncModule {
    // Usage: describe the main section of the bus slave.

public:
    virtual void ConnectBusSlvIntf(CmBusMstIntf *bus_mst_intf) {
        // Usage: connect the circuit to the bus slave interface.
    }

    virtual RDATA ReadBusSlave(ULONG address, int byte_count) = 0;
        // Usage: read the value from the circuit to the bus.

    virtual int WriteBusSlave(ULONG address, ULONG data,
        int byte_count) = 0;
        // Usage: write the value from the bus into the object.
};
```

FIG. 18

```

class CmBusMstIntf : public CmSyncModule {
// Usage: create a bus master interface.

public:
    virtual bool IsBusReq(void) {
// Usage: returns a value indicating whether the bus master
// interface requests to use the bus.
    }
    virtual void AssertBusGnt(void) {
// Usage: notify the bus master interface of the permission
// use the bus, which is sent from an external circuit
// (normally, the arbiter).
    }
    virtual void DeassertBusGnt(void) {
// Usage: notify the bus master interface of the rejection
// to use the bus, which is sent from an external circuit
// (normally, the arbiter).
    }
    virtual void AppendWriteData(int mode, ULONG address,
                                ULONG data, int byte_count) {
// Usage: when mode is 0, register address which is to be written
// into the circuit module through the bus, data, and the
// number of bytes byte_count, in the buffer of the circuit
    }
    virtual void StartWrite(int mode) {
// Usage: when mode is 0, start writing data into the bus.
    }
    virtual bool IsWriteEnd(int mode) {
// Usage: when mode is 0, return a value
// indicating whether the writing is completed.
    }
    virtual void AppendReadAddress(int mode,
                                ULONG address, int byte_count) {
// Usage: when mode is 0, register address which is to be
// written into the circuit module through the bus,
// data, and the number of bytes byte_count,
// in the buffer of the circuit
    }
}

```


FIG. 19

(continued from the definition of class CmBusMstIntf)

```

virtual void StartRead(int mode) {
// Usage: when mode is 0, start reading the data from the bus.
}

virtual bool IsReadEnd(int mode) {
// Usage: when mode is 0, return a value indicating whether
// the reading operation from the bus is completed.
}

virtual ULONG GetReadData(int mode){
// Usage: when mode is 0, and when the reading from the bus is
// completed, extract data which has been read and
// stored in the buffer and return the data to the bus master.
}

virtual void OneStep(void) {
// Usage: operate the circuit by one step.
// Operation: while in the reading or writing operation from the
// bus master to the bus, extract one data, to be read
// or written, from the buffer, and send it to the bus.
// When the buffer becomes empty,
// the reading or writing is completed.
// Supplement: OneStep function defined in
// CmSyncModule is overridden.
}
};

```

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FIG. 20

```

class CmBusSlvIntf : public CmSyncModule {
public:
    virtual bool IsBusReq(void) {
        // Usage: return a value indicating whether the bus
        //         slave interface requests to use the bus.
    }
    virtual void AssertBusGnt(void) {
        // Usage: the external circuit (normally, the arbiter) notifies the
        //         bus slave interface of the permission to use the bus.
    }
    virtual void DiassertBusGnt(void) {
        // Usage: the external circuit (normally, the arbiter)
        //         notifies the bus slave interface of the prohibition
        //         to use the bus.
    }
    virtual void AppendWriteData(int mode, ULONG address,
                                ULONG data, int byte_count) {
        // Usage: when mode is 0, register address which is to be
        //         written into the bus slave, data, and the number of
        //         bytes byte_count, into the buffer of the circuit
    }
    virtual void StartWrite(int mode) {
        // Usage: when mode is 0, write the data into the bus slave,
        //         based on the data registered in the buffer.
    }
    virtual bool IsWriteEnd(int mode) {
        // Usage: when mode is 0, return a value indicating whether the
        //         writing operation into the bus slave completed.
    }
    virtual void AppendReadAddress(int mode, ULONG address,
                                   int byte_count) {
        // Usage: when mode is 0, the address, which is to be read from
        //         the bus slave, and the number of bytes byte_count into
        //         the buffer in the circuit.
    }
}

```

FIG. 21

(continued from the definition of class CmBusSivIntf)

```
virtual void StartRead(int mode) {

    // Usage: when mode is 0, read the data from the bus slave,
    //         // based on the data registered in the buffer.
    virtual bool IsReadEnd(int mode) {
        // Usage: when mode is 0, return a value indicating whether
        //         // the reading operation from the bus slave is completed.
    }
    virtual ULONG GetReadData(int mode){
        Usage: when mode is 0, and when the reading operation from the
        //       bus slave is completed, extract data which has been read
        //       from the bus slave and has been stored in the buffer,
        //       and return it to the bus.
    }
    virtual void OneStep(void) {

        // Usage: operate the circuit by one step.
        // Operation: OneStep does not perform operation
        //              in connection with the bus slave.
        // Supplement: CmBusSivIntf overrides OneStep defined in SyncModule.

    }
};
```

FIG. 22

```

class CmBusSystem : public CmSyncModule {
public:
    virtual void ConnectBusMstIntf(CmBusMstIntf *bus_mst_intf) {
        // Supplement: CmBusSlvIntf overrides OneStep defined in SyncModule.
    }
    virtual void ConnectBusSlvIntf(CmBusSlvIntf *bus_slv_intf) {
        // Usage: connect the bus slave interface to the bus.
    }
    virtual void SetUserReadMap(CmHier *hier) {
        // Usage: designate a bus read map. When sending the object of
        // CmHier class, the UserReadMap function of CmHier object is
        // registered as the bus read map of the bus.
    }
    virtual void SetUserWriteMap(CmHier *hier) {
        // Usage: designate a bus write map. When sending the object of
        // CmHier class, the UserWriteMap function of CmHier object is
        // registered as the bus write map of the bus.
    }
    virtual void SetUserArbitor(CmHier *hier) {
        // Usage: designate an arbiter. When sending the object of
        // CmHier class, the UserArbitor function of CmHier object is
        // registered as the arbiter of the bus.
    }
    virtual RDATA ReadMap(ULONG address, int byte_count) {
        // Usage: read data from a circuit module through the bus.
        // Based on the given address, the circuit which is the target to be
        // read is determined. The data of the number of bytes byte_count are
        // read from the circuit module, and the read data is returned.
    }
    virtual int WriteMap(ULONG address, ULONG data, int byte_count) {
        // Usage: write data into a circuit module through the bus.
        // Based on the given address, the circuit to which the data is to be
        // written is determined. The data of the number of bytes byte_count
        // are written into the circuit module, and a value indicating whether
        // the writing is successful is returned.
    }
    virtual void OneStep(void) {
        // Usage: operate the bus arbiter by one step.
        // Operate the information display function of the bus.
        // Supplement: because the bus is a simple signal line,
        // the bus does not operate in response to the clock.
    }
};

```

FIG. 23

```
class CmHier : public CmSyncModule {
    virtual RDATA UserReadMap(ULONG address, int byte_count) {
        // Usage: describe the bus read map of the bus
        //          included in the system.
    }
    virtual int UserWriteMap(ULONG address, ULONG data,
                           int byte_count) {
        // Usage: describe the bus write map of the bus
        //          included in the system.
    }
    virtual void UserArbitor(void) {
        // Usage: describe the arbiter of the bus
        //          included in the system.
    }
}
```

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FIG. 24

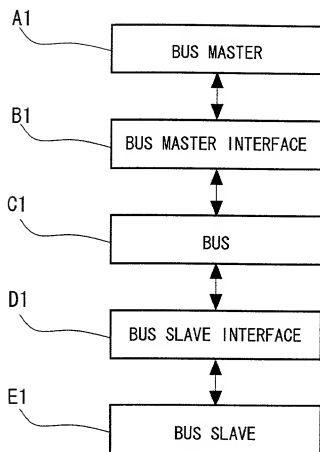
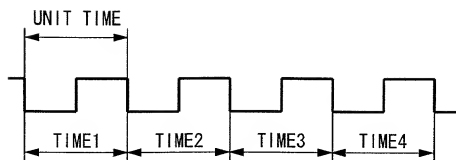


FIG. 25

ADDRESS	DATA	NUMBER OF BYTES
0x00100000	0x00112233	4
0x00100004	0x44556677	4

FIG. 26



time1

FIG. 27

OneStep of A1

A1 executes AppendWriteData(0, 0x00100000, 0x00112233, 4) of B1.

B1 stores the data into the buffer.

A1 executes AppendWriteData(0, 0x00100004, 0x44556677, 4) of B1.

B1 stores the data into the buffer.

A1 executes StartWrite(0) of B1.

B1 memorizes the write request.

A1 executes IsWriteEnd(0) of B1.

B1 returns a value indicating that B1 is writing the data.

A1 goes on standby.

OneStep of B1

Because B1 is requested by A1 to write the data,

B1 requests to use the bus.

When the IsBusReq function of the bus master interface B1 is externally executed, the return value is true.

OneStep of C1

Operate the arbiter.

Arbiter executes IsBusReq() of B1.

B1 returns that B1 is requesting to use the bus.

Arbiter permits B1 to use the bus.

Arbiter executes AssertBusGnt() of B1.

B1 memorizes the permission to use the bus.

OneStep of D1

no operation

OneStep of E1

The special operation of the bus slave E1 is performed,
but does not includes an operation in connection with the bus.

time

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FIG. 28

#time2

OneStep of A1

A1 executes IsWriteEnd(0) of B1.

B1 returns that B1 is writing the data.

A1 goes on standby.

OneStep of B1

Because B1 is permitted to use the bus,

B1 writes the data into the bus.

That is, the following operations are performed.

B1 extracts one data from the buffer.

address:0x00100000 data:0x00112233 number of bytes:4

B1 executes WriteMap(0x00100000, 0x00112233, 4) of C1.

WriteMap function of C1 executes the following operations.

Execute AppendWriteData(0, 0x00100000, 0x00112233, 4)

function of D1.

D1 stores the given data into the buffer.

D1 executes StartWrite(0) function.

D1 executes WriteBusSlave(0x00100000, 0x00112233, 4)

function of E1.

E1 internally writes the given data,

and returns a value, indicating whether the

writing is successful, to D1.

In the example, the writing is successful.

Execute IsWriteEnd(0) function of D1.

Because the writing operation by D1 into E1 is

successful, the value is true.

Return the return value of IsWriteEnd(0) function D1.

B1 comes to know that the data has been successfully written,
based on the return value.

Then, B1 deletes data from the buffer.

Because B1 stores data, the same process is performed

in the next OneStep of B1.

OneStep of C1

no operation

OneStep of D1

no operation

OneStep of E1

The special operation of the bus slave E1 is performed,

but does not includes an operation in connection with the bus.

time

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FIG. 29

#time3

OneStep of A1

A1 executes IsWriteEnd(0) of B1.

B1 returns that B1 is writing the data.

A1 stays on standby.

OneStep of B1

Because B1 is permitted to use the bus, B1 writes the data into the bus.

That is, the following operations are performed.

B1 extracts one data from the buffer.

address: 0x00100004 data: 0x44556677 number of bytes: 4

B1 executes WriteMap(0x00100004, 0x44556677, 4) of C1.

WriteMap function of C1 performs the following operations.

Execute AppendWriteData(0, 0x00100004, 0x44556677, 4)
function of D1.

D1 stores the given data into the buffer.

Execute StartWrite(0) function of D1.

D1 executes WriteBusSlave(0x00100004, 0x44556677, 4)
function of E1.

E1 internally writes the given data, and returns a value,
indicating whether the writing is successful, to D1.

In the example, the writing is successful.

Execute IsWriteEnd(0) function of D1.

Because the writing from D1 into E1 has been successful,
the return value is true.

Return IsWriteEnd(0) function of D1.

B1 comes to know that the data has been successfully written,
based on the return value.

Then, B1 deletes one data from the buffer.

There is no data in the buffer of B1.

B1 completes the writing operation.

The return value of IsWriteEnd(0) function of B1 is true.

OneStep of C1

no operation

OneStep of D1

no operation

OneStep of E1

The special operation of the bus slave E1 is performed,

but does not includes an operation in connection with the bus.

time

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FIG. 30

#time4

OneStep of A1

A1 executes IsWriteEnd(0) of B1.

B1 returns a value indicating that the writing is completed.

A1 starts the next operation.

OneStep of B1

no operation.

OneStep of C1

no operation

OneStep of D1

no operation

OneStep of E1

The special operation of the bus slave E1 is performed.

but does not includes an operation in connection with the bus.

time

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FIG. 31A

Statement of ClassX

```

class ClassX{
    CmBusMstIntf *BusMstIntf;
    void ConnectBusMstIntf(CmBusMstIntf *busif) {
        BusMstIntf=busif;
    }
    void OneStep(void) {
        ...
        BusMstIntf->AppendReadData (...);
        BusMstIntf->StartRead (...);
        ...
    }
}

```

[1] points to the opening curly brace of the class definition.

[2] points to the `AppendReadData (...)` call.

[3] points to the `StartRead (...)` call.

FIG. 31B

Schematic Diagram

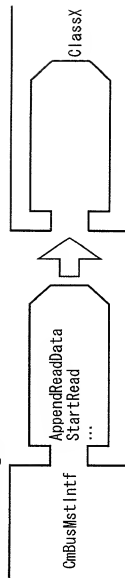


FIG. 32A

Example 1 of Statement of System

```

main() {
  ClassX ObjectX;      [1]
  OnPciBusMstIntf PciBusMstIntf;  [2]
  ...
  ObjectX.ConnectBusMstIntf(&PciBusMstIntf);  [3]
  ...
}

```

FIG. 32B

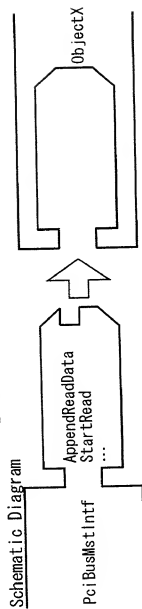


FIG. 33A

Example 2 of Statement of System

```

main() {
    ClassX ObjectX;
    CUserBusMstIntf UserBusMstIntf;
    ...
    ObjectX.ConnectBusMstIntf(User&BusMstIntf);
    ...
}

```

FIG. 33B

Schematic Diagram

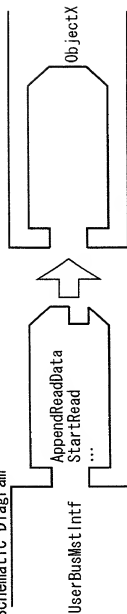


FIG. 34A

Statement of ClassY

```

class ClassY{
  OnComponent *PointerComponent
  void ConnectComponent (OnComponent *c) {
    PointerComponent=c;
  }
  void OneStep (void) {
    ...
    ...=PointerComponent->GetPinValue();
    ...
  }
};

```

[1] points to `OnComponent *PointerComponent`

[2] points to `...=PointerComponent->GetPinValue();`

FIG. 34B

Schematic Diagram

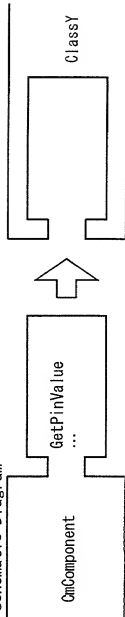


FIG. 35A

Example of Statement of System

```
main() {
  ClassY ObjectY;
  CUserCpu UserCpu;  — [1]
  ...
  ObjectY.YConnectComponent(&UserCpu);
  ...
}
```

FIG. 35B

Schematic Diagram

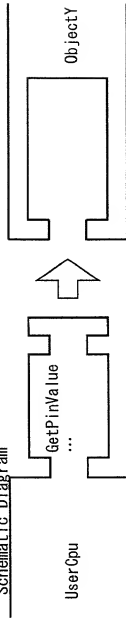


FIG. 36A

Statement in C++

```

main() {
    OnBusSlave BusSlave;
    OnBusMstIntf BusMstIntf;
    ...
    BusSlave.ConnectBusSlvIntf(&BusMstIntf); //Error
    ...
}

```

[1]

Schematic Diagram FIG. 36B

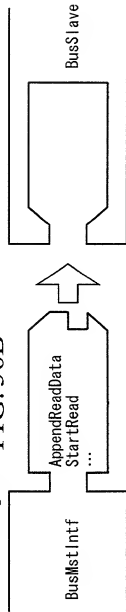


FIG. 37A

Statement in HDL

```
module C:
  wire c1, ...
  ModuleA A(.a1(c1), ...);
  ModuleB B(.b1(c1), ...);
endmodule
```

FIG. 37B

Schematic Diagram

